CLAIMS

1. Method for controlling a first robot (1) and at least
   one other robot (2), the at least one other robot (2)
   being calibrated relative to the first robot by the de-
5 termination of at least one coordinate transformation
   (SF1-2) of the first robot relative to at least one
   other robot and said at least one transformation (SF1-
   2) is stored in a control device (2.1) of the other ro-
   bot, wherein also the first robot (1) is calibrated re-
10 lative to the other robot (2) by the determination of
   at least one independent coordinate transformation
   (SF2-1) and said at least one independent transformati-
   on (SF2-1) is stored in a control device of the first
   robot.
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2. Method according to claim 1, wherein in the case of at
   least three robots, each robot is calibrated relative
   to the others by at least one independent determination
   of coordinate transformations and the at least one
20 transformation of the calibration of each robot is sto-
   red in a control device thereof.

3. Method according to claim 1, wherein for each robot se-
   veral calibrations are performed each at different po-

sitions and the thus obtained transformations (SF2-1, SF1-2) are stored.

4. Method according to claims 1, wherein the calibrations for each robot (1, 2) are performed at different positions.

5. Method according to claim 1, wherein in the case of cooperative operation of at least two robots (1, 2), the coordinates of the independent robot (1, 2) and the coordinates transformed relative thereto (on the basis of SF2-1 or SF1-2) of the independent robot or robots (2, 1) are used.

6. Method according to claim 3, wherein in operating area-dependent manner, the coordinates of one robot and the coordinates of one or other robots transformed thereto are used.

7. Method according to claim 1, wherein in the cooperative operation of at least two robots (1, 2), as desired, one (1, 2) of the robots is used as the independent robot and the at least one other robot (2, 1) as a dependent robot.

8. Method according to claim 7, wherein during an operating process the characteristic of the robots (1, 2) as an independent or dependent robot is changed.

9. System for controlling a first robot (1) and at least one other robot (2) with at least one control means (1.1, 2.1) with a device (2.2) for calibrating at least one other robot (2) relative to the first robot (1) by determining at least one coordinate transformation (SF1-2) of the first robot (10 relative to the other

robot (2) and with a memory means (2.3) in the control
device (2.1) of the other robot (2) for storing said at
least one transformation (SF1-2), having determination
means (1.2) for calibrating the first robot (1) relati-
5   ve to the other robot (2) by determining at least one
independent coordinate transformation (SF2-1) of at le-
ast one other robot (2) relative to the first robot (1)
and by a memory means (1.3) in a control device (1.1)
of the first robot (1) for storing at least one inde-
10   pendent transformation (SF2-1).

10. System according to claim 9, with at least three ro-
bots, wherein each of the robots (1, 2) in its control
device (1.1, 1.2) has a means for its calibration (1.2,
15   1.2) relative to each of the other robots (2, 1) by de-
termining at least one coordinate transformation (SF2-
1, SF1-2) relative to each of the other robots (2, 1),
as well as a memory means (1.3, 2.3) for storing the in
each case at least one coordinate transformation (SF2-
20   1, SF1-2).

11. System according to claim 9 designed for calibrating
each robot (1, 2) by several transformations and for
the storage of several such transformations.
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12. System according to one of the claims 9 to 11, designed
for calibrating the robots (1, 2) at different locati-
ons.

30 13. System according to claim 9, characterized by the use
of the coordinates of an independent robot and the
transformed coordinates of the at least one dependent
robot during cooperative operation of at least two ro-
bots.

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14. System according to claim 9, designed for using the
    coordinates of one robot and the coordinates of the
    other robot or robots transformed relative thereto in
    different areas of operation.

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15. System according to claim 9, designed for chouceable
    use of one robot as an independent robot and the at le-
    ast one other robot as a dependent robot during coope-
    rative operation of at the least two robots.

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16. System according to claim 15, designed for changing the
    characteristic of the robots as independent or depen-
    dent robots during an operating process.